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Tachibana et al.

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(54) **METHOD AND APPARATUS FOR AZIMUTH DETECTION**

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G01S 19/235; G01S 2007/403; G01S

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H01R 24/68; H01R 39/64; H01R 39/643

See application file for complete search history.

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(21) Appl. No.: **14/992,090**

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(51) **Int. Cl.**
H04W 72/04 (2009.01)
H04W 4/02 (2018.01)
H04W 16/28 (2009.01)
H04W 4/80 (2018.01)

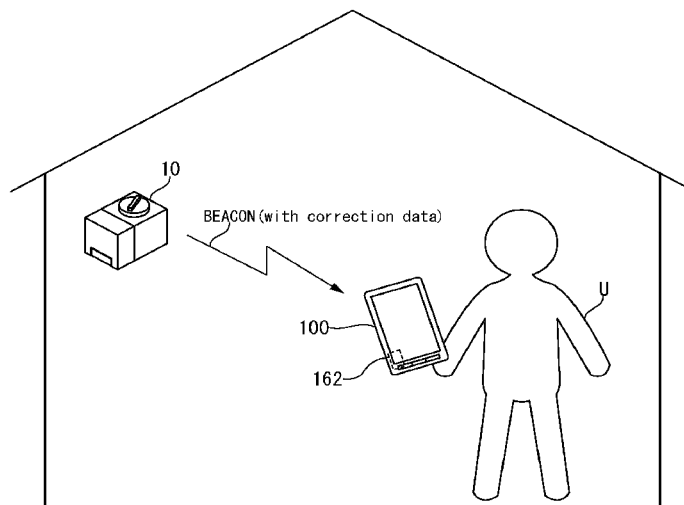
(52) **U.S. Cl.**
CPC **H04W 72/046** (2013.01); **H04W 4/026** (2013.01); **H04W 4/80** (2018.02); **H04W 16/28** (2013.01)

(58) **Field of Classification Search**
CPC ... H04W 72/046; H04W 4/008; H04W 4/026;

(57) **ABSTRACT**

Aspects of the disclosure provide a radio transmitting device that includes a memory, a controller and a wireless communication processing circuit. The memory is configured to store correction data for correcting an azimuth angle detected by a device in a surrounding range around a location where the radio transmitting device is installed. The controller is configured to read the correction data from the memory. The wireless communication processing circuit is configured to transmit a radio signal to carry the correction data to assist the device in the surrounding range to correct the azimuth angle.

20 Claims, 11 Drawing Sheets



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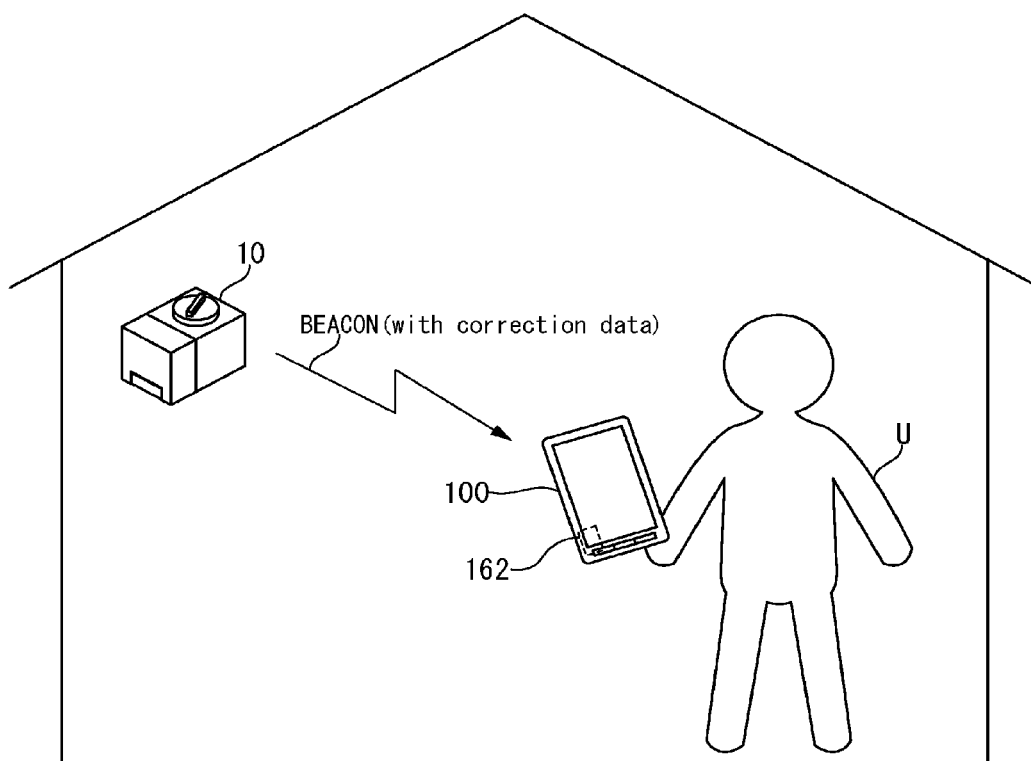
FIG. 1

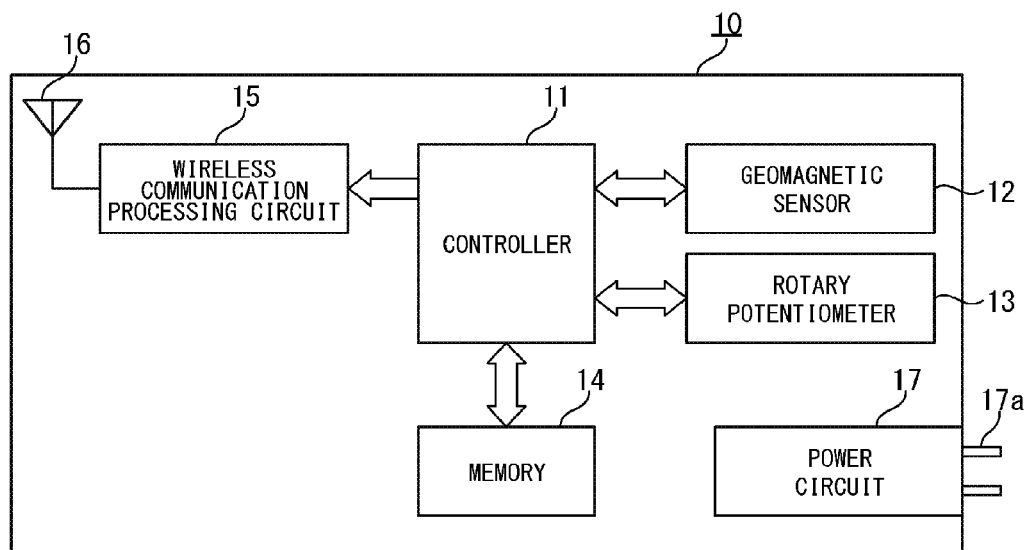
FIG. 2

FIG. 3A

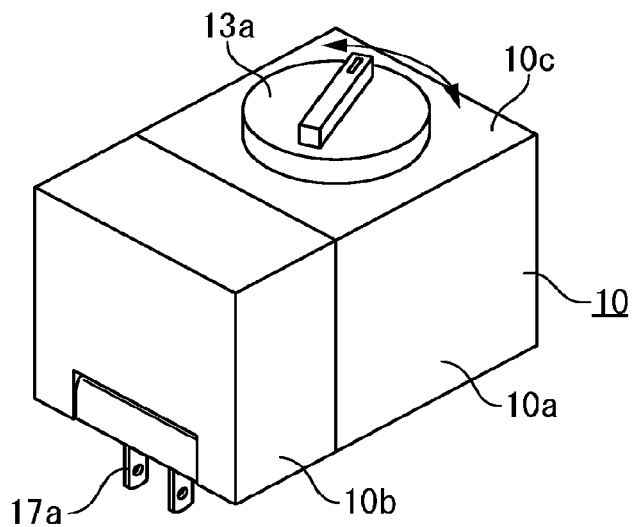


FIG. 3B

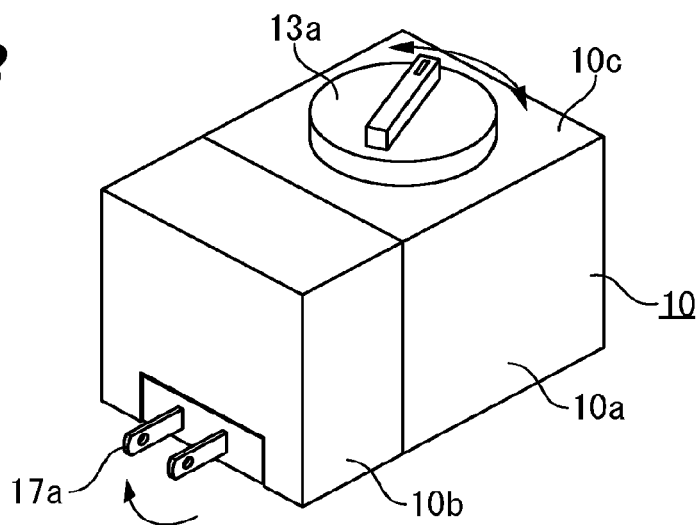


FIG. 3C

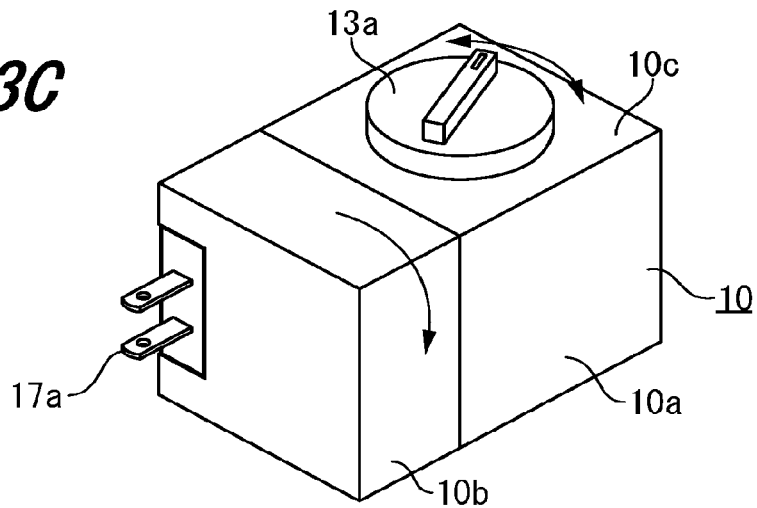


FIG. 4A

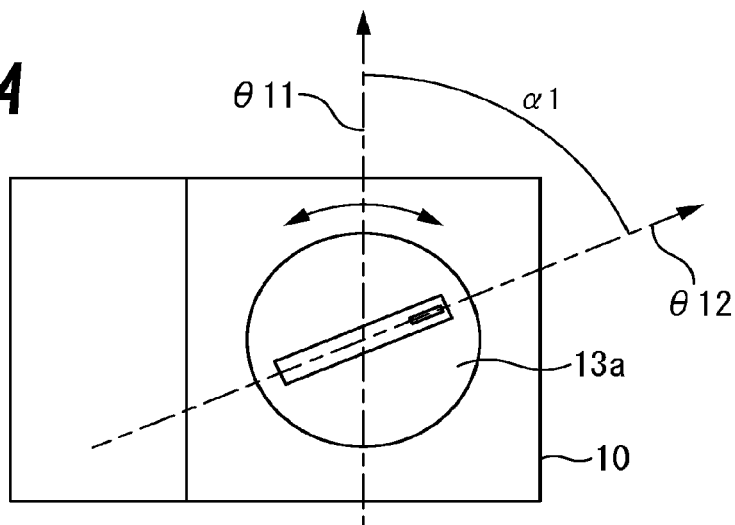


FIG. 4B

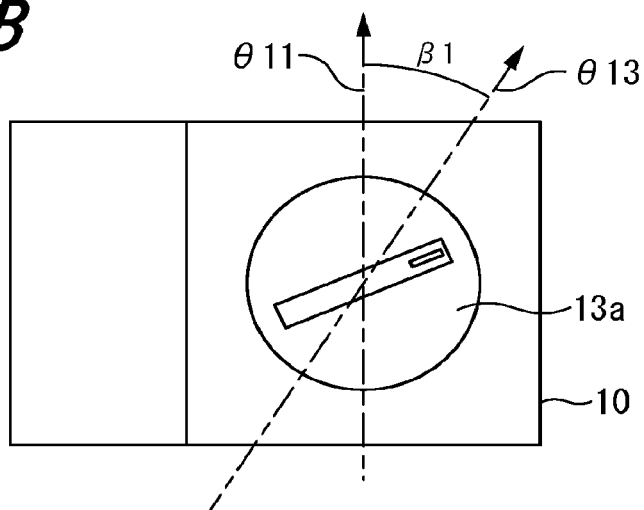


FIG. 4C

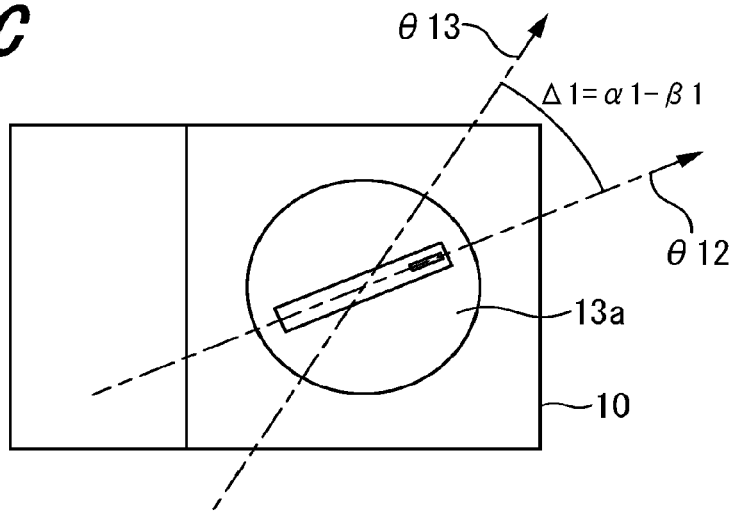


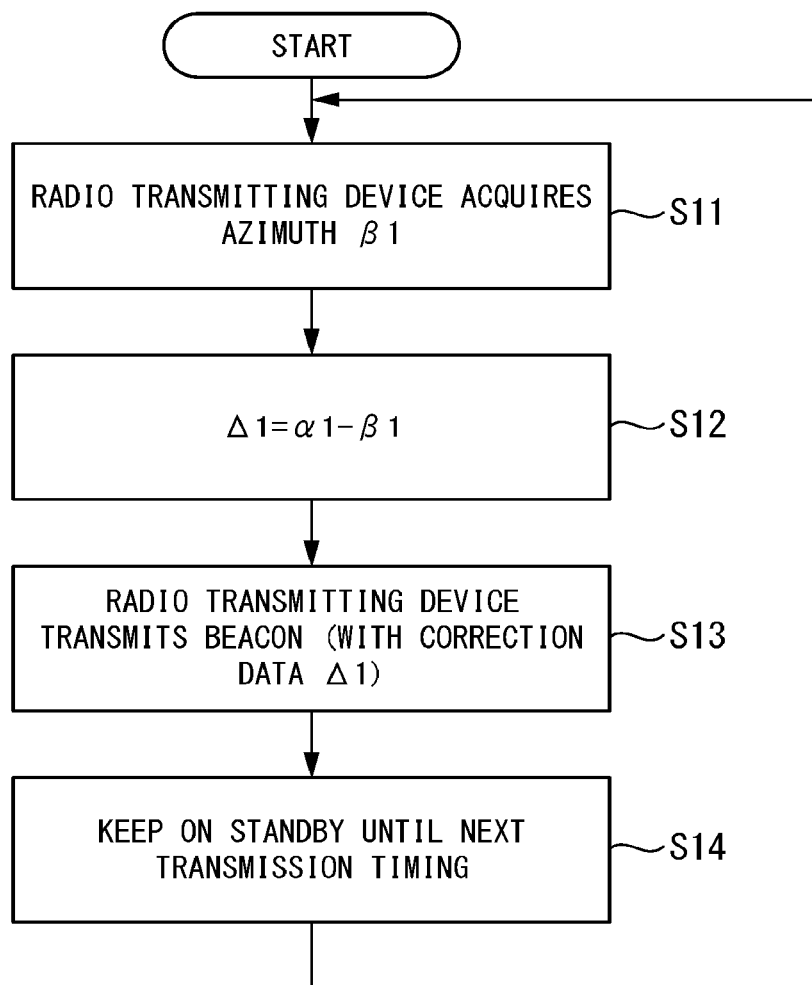
FIG. 5

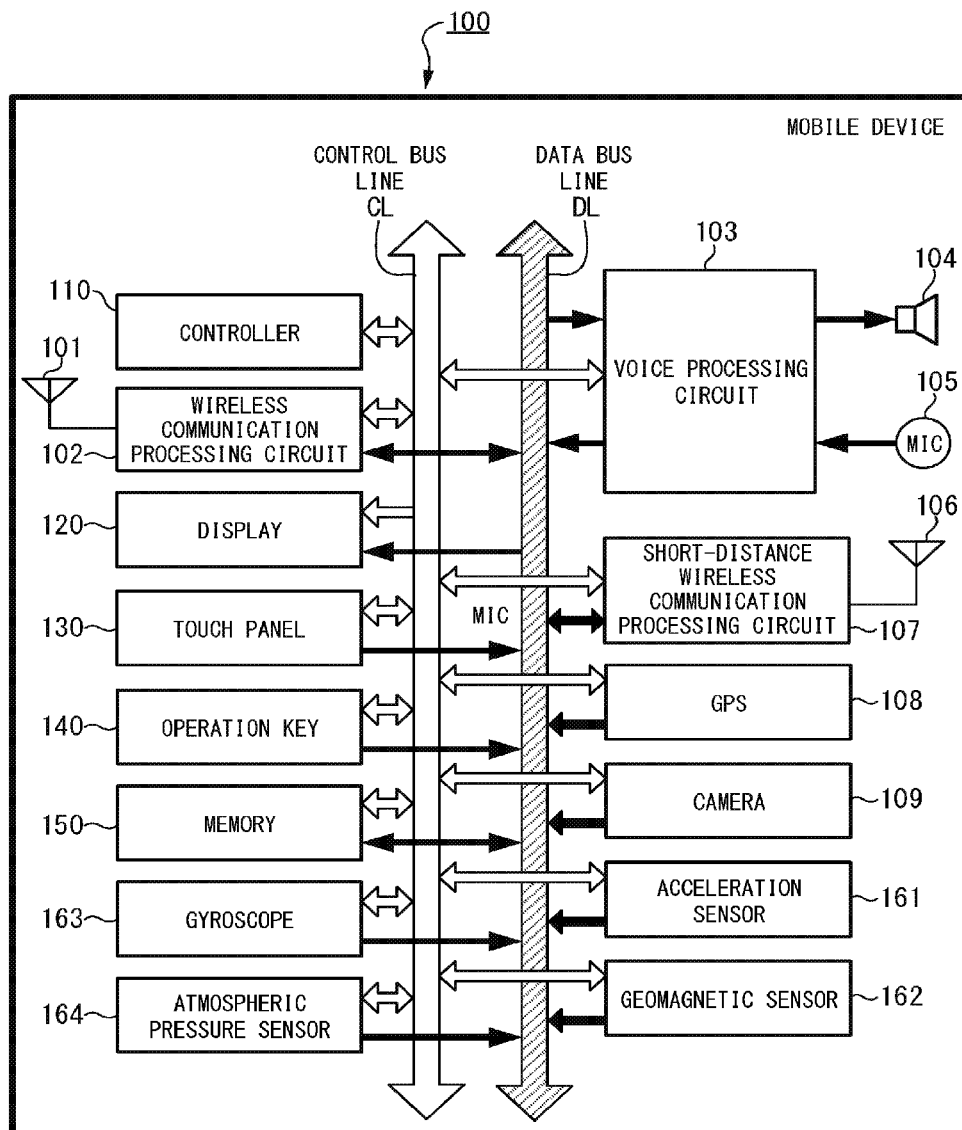
FIG. 6

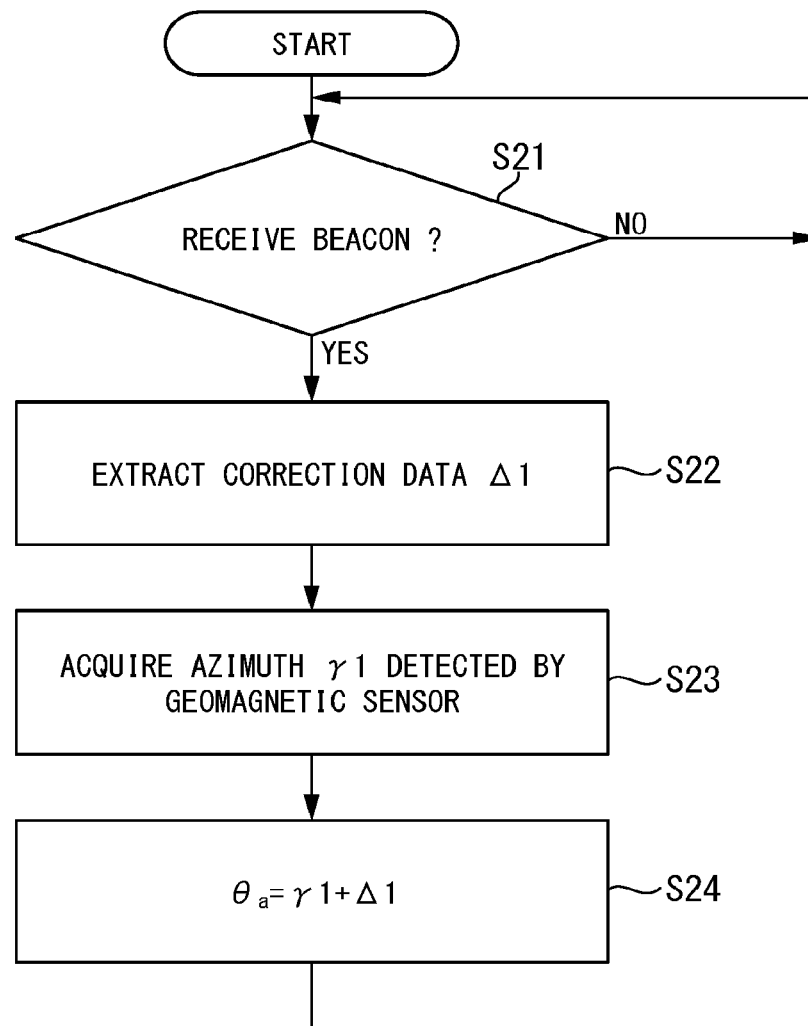
FIG. 7

FIG. 8

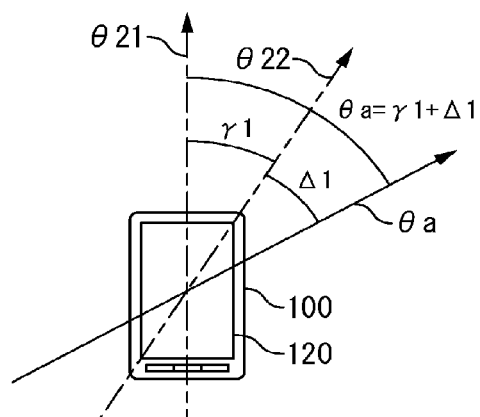


FIG. 9

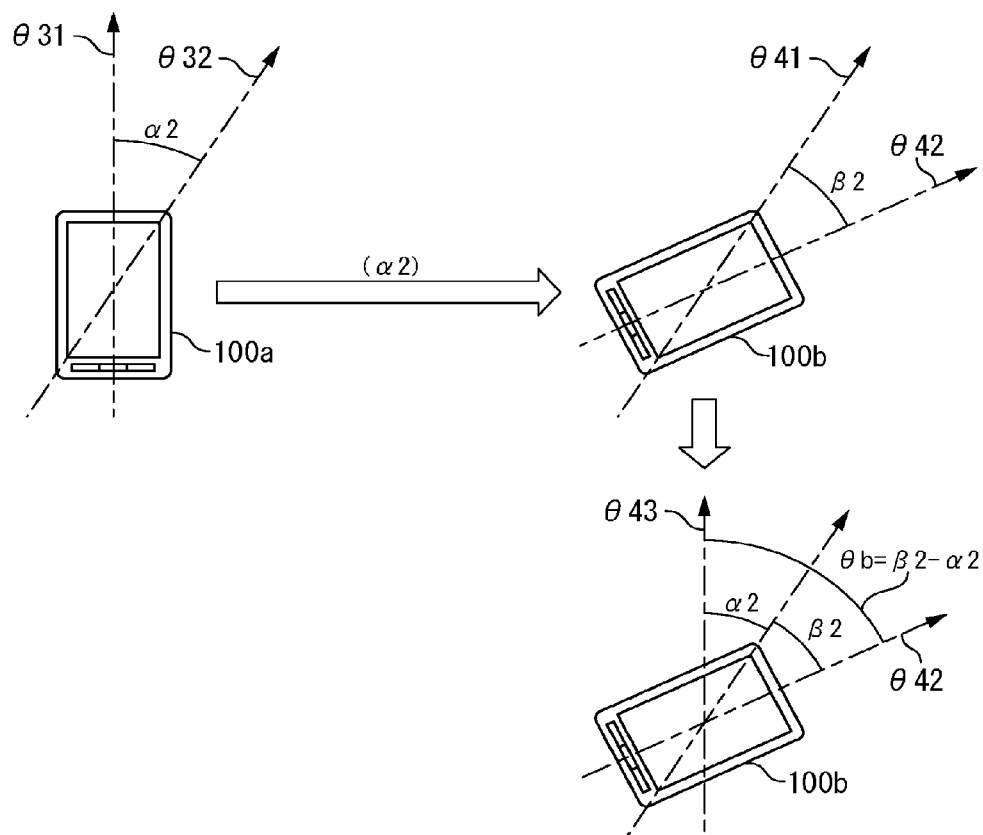


FIG. 10A

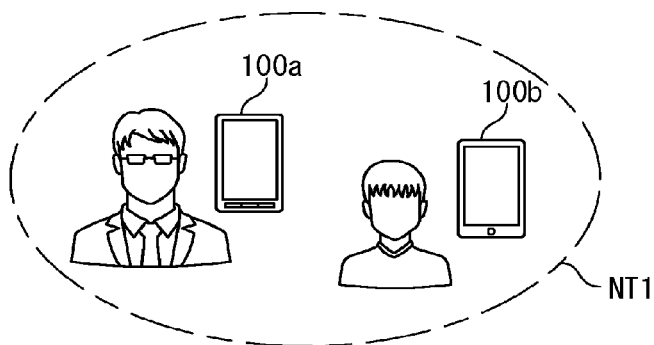


FIG. 10B

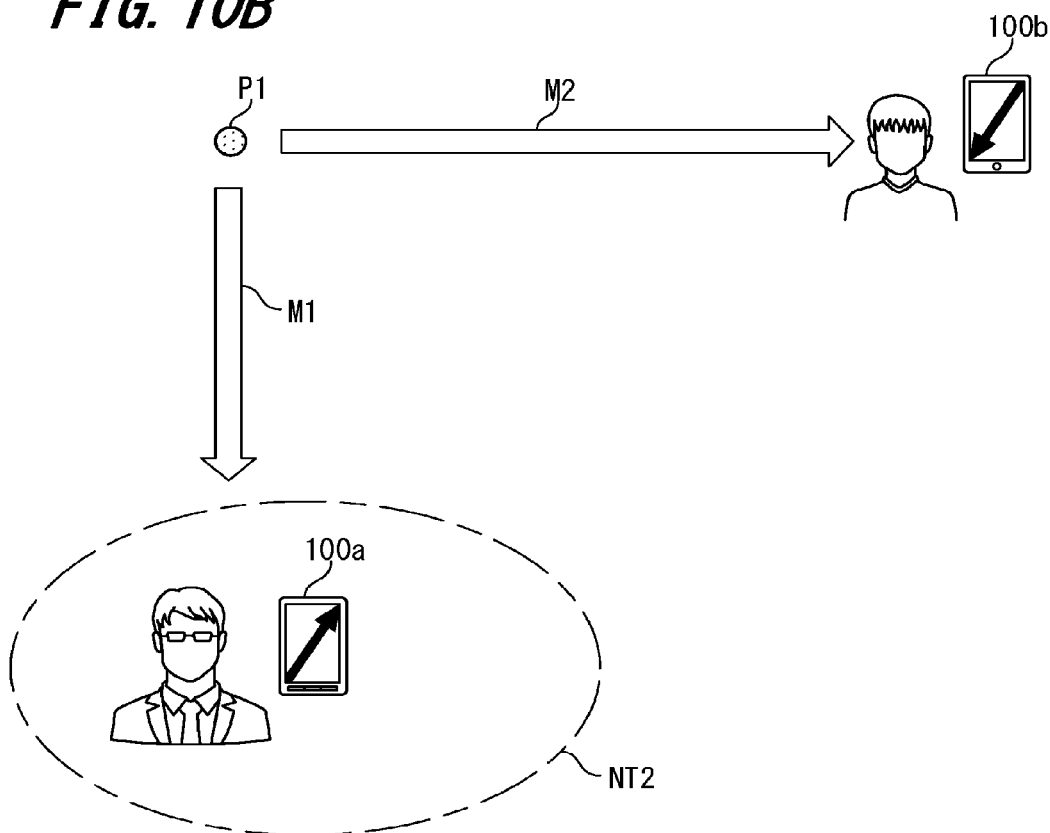


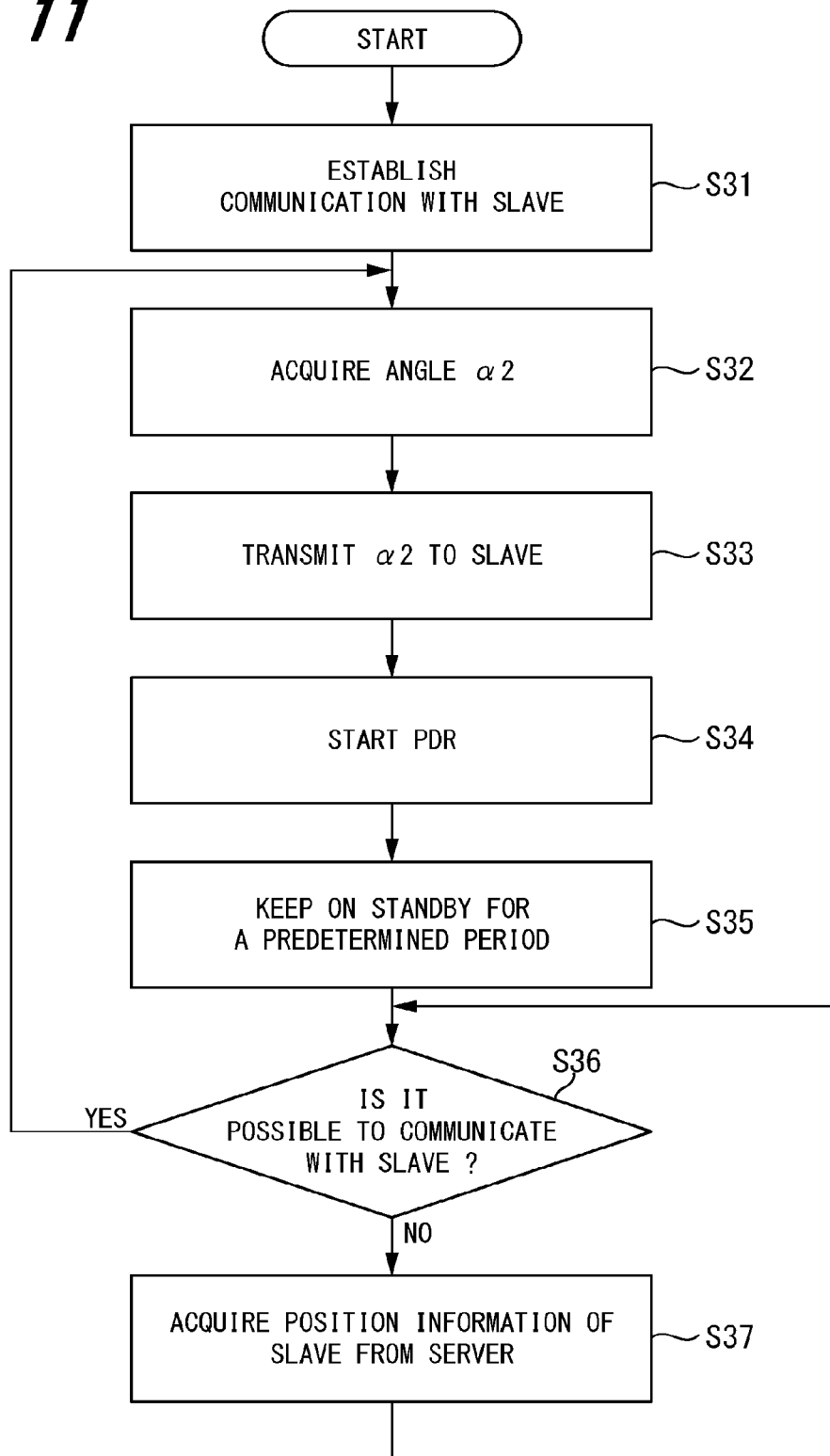
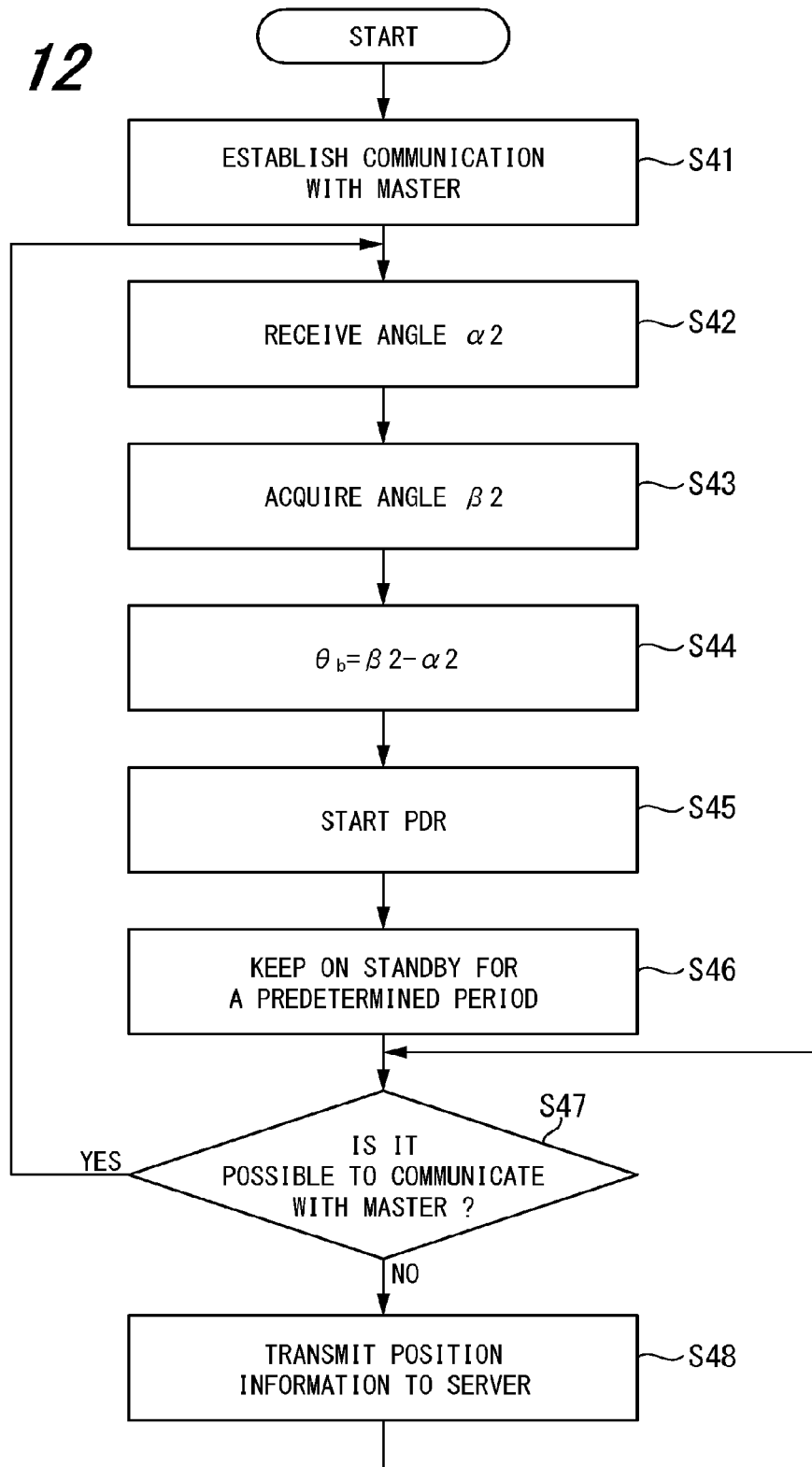
FIG. 11

FIG. 12

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METHOD AND APPARATUS FOR AZIMUTH DETECTION

INCORPORATION BY REFERENCE

This present disclosure claims the benefit of U.S. Provisional Application No. 62/199,772, "METHOD AND APPARATUS FOR AZIMUTH DETECTION" filed on Jul. 31, 2015, which is incorporated herein by reference in its entirety.

TECHNICAL FIELD

This disclosure is related to a wireless transmitter which transmits a beacon signal to mobile devices, such as a smart phone, and the like to assist azimuth detection.

DESCRIPTION OF RELATED ART

The background description provided herein is for the purpose of generally presenting the context of the disclosure. Work of the presently named inventors, to the extent the work is described in this background section, as well as aspects of the description that may not otherwise qualify as prior art at the time of filing, are neither expressly nor impliedly admitted as prior art against the present disclosure.

A mobile device, such as a smart phone, a tablet computer and the like, can include a positioning system, such as Global Positioning System (GPS), to measure a position of the mobile device. In an example, the GPS receives the electromagnetic wave from one or more satellites, and measures present position based on the electromagnetic wave. Generally, the GPS based positioning is used outdoors where the GPS can receive the electromagnetic wave from the satellites. Indoors, in an example, a mobile device uses an autonomous navigation system to detect present position. For example, the autonomous navigation system includes a geomagnetic sensor and an acceleration sensor. The geomagnetic sensor detects an azimuth and the acceleration sensor detects a movement distance. The mobile device can calculate present position using the information of the azimuth and the movement distance.

SUMMARY

Aspects of the disclosure provide a radio transmitting device that includes a memory, a controller and a wireless communication processing circuit. The memory is configured to store correction data for correcting an azimuth angle detected by a device in a surrounding range around a location where the radio transmitting device is installed. The controller is configured to read the correction data from the memory. The wireless communication processing circuit is configured to transmit a radio signal to carry the correction data to assist the device in the surrounding range to correct the azimuth angle.

In an embodiment, the wireless communication processing circuit is configured to transmit the radio signal as a beacon signal that is transmitted periodically to carry the correction data.

According to an aspect of the disclosure, the radio transmitting device includes a geomagnetic sensor configured to measure an azimuth angle at the location. Further, the radio transmitting device includes a reference angle device, such as a potentiometer, and the like configured to generate an electrical signal in response to a reference angle. The

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controller is configured to calculate the correction data based on the reference angle and the azimuth angle detected by the geomagnetic sensor.

Further, according to an aspect of the disclosure, the radio transmitting device includes a plug for connection to an AC power source and a rotary mechanism configured to adjust a relative angle between the plug and the potentiometer.

Aspects of the disclosure also provide a mobile device that includes a geomagnetic sensor, a wireless communication processing circuit and a controller. The geomagnetic sensor is configured to detect an azimuth angle. The wireless communication processing circuit is configured to receive a radio signal carrying correction data for correcting the azimuth angle. The controller is configured to correct the azimuth angle detected by the geomagnetic sensor based on the correction data carried in the radio signal.

Aspects of the disclosure also provide a method for detecting azimuth angle. The method includes receiving, by a wireless communication processing circuit in a mobile device, a radio signal carrying correction data for azimuth angle correction, detecting, by a geomagnetic sensor, an azimuth angle, and correcting the azimuth angle based on the correction data carried in the radio signal.

BRIEF DESCRIPTION OF THE DRAWINGS

Various embodiments of this disclosure that are proposed as examples will be described in detail with reference to the following figures, wherein like numerals reference like elements, and wherein:

FIG. 1 shows a diagram for azimuth detection according to an embodiment of the disclosure;

FIG. 2 shows an example of the radio transmitting device according to an embodiment of the disclosure;

FIG. 3A, FIG. 3B, and FIG. 3C are figures showing an example of a case structure of the radio transmitting device according to an embodiment of the disclosure;

FIG. 4A, FIG. 4B, and FIG. 4C are the figures explaining an example how the radio transmitting device outputs correction data according to an embodiment of the disclosure;

FIG. 5 shows a flowchart outlining a process executed by the controller 11 of the radio transmitting device 10;

FIG. 6 shows a block diagram of the mobile device 100 according to an embodiment of the disclosure;

FIG. 7 shows a flowchart outlining an example of a correction process according to an embodiment of the disclosure;

FIG. 8 shows an example of the azimuth correction process according to an embodiment of the disclosure;

FIG. 9 is a diagram of another example of azimuth detection according to an embodiment of the disclosure;

FIGS. 10A and 10B show an example in which the mobile devices 100a, 100b respectively perform an autonomous navigation independently;

FIG. 11 shows a flowchart outlining a process example executed by the controller 110 of the master mobile device 100a; and

FIG. 12 shows a flowchart outlining a process example executed by the controller 110 in the slave mobile device 100b.

DETAILED DESCRIPTION OF EMBODIMENTS

FIG. 1 shows a diagram for azimuth detection according to an embodiment of the disclosure. In the FIG. 1 example, a mobile device 100 receives a radio signal from a radio

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transmitting device **10**. The radio signal carries azimuth correction information to assist the mobile device **100** to perform azimuth detection.

The mobile device **100** can be any suitable device, such as a smart phone, a tablet computer, a laptop computer, a wearable electronic device, a cellular phone, a music player, a camera, and the like. In an example, the mobile device **100** is owned by a user U, and the user U moves around with the mobile device **100**.

In an embodiment, the radio transmitting device **10** is installed inside a building. In an example, the radio transmitting device **10** transmits the radio signal repeatedly, for example, at regular intervals. The radio signal is referred to as a beacon signal in some example. The radio signal can be transmitted according to any suitable wireless technology and/or standard. In an example, the radio signal is transmitted according to a short-distance wireless communication standard, such as Bluetooth Low Energy (BLE), and the like.

The radio signal transmitted by the radio transmitting device **10** carries various information. In an example, the radio signal carries an identification code which uniquely identifies the radio transmitting device **10** from other radio transmitting devices. Further, the radio signal carries azimuth correction information. In an example, the azimuth correction information is indicative of an error between an azimuth detected by a geomagnetic sensor and a true azimuth.

In the FIG. 1 example, the mobile device **100** includes a geomagnetic sensor **162** configured to detect the azimuth. When the mobile device **100** is at a location able to receive the radio signal, the mobile device **100** corrects the detected azimuth based on the azimuth correction information in the radio signal. Based on the corrected azimuth and other suitable information, the mobile device **100** detects the present position, for example using an autonomous navigation system. In the autonomous navigation system, the determined position is a relative position from a reference position.

According to an aspect of the disclosure, the azimuth detected by a geomagnetic sensor varies in different surrounding environment. In an example, in a building, the azimuth detected by a geomagnetic sensor varies from several degrees to several dozen degrees from a true azimuth due to the influences of building materials, such as the steel frame and the like. In another example, the azimuth detected by a geomagnetic sensor outdoors may change due to the influence of the surrounding buildings, and the like. When the azimuth angle detected by the geomagnetic sensor **162** has errors due to the effect the buildings and/or the like, the determined position by the mobile device **100** using the autonomous navigation has errors. When errors in the azimuth detection are corrected, the autonomous navigation system can provide more accurate position detection.

FIG. 2 shows an example of the radio transmitting device **10** according to an embodiment of the disclosure. The radio transmitting device **10** includes a controller **11**, a geomagnetic sensor **12**, a rotary potentiometer **13**, a memory **14**, a wireless communication processing circuit **15**, an antenna **16**, and a power supply circuit **17** coupled together as shown in FIG. 2.

The geomagnetic sensor **12** detects a direction of a terrestrial magnetism, and then detects an azimuth. In an example, the geomagnetic sensor **12** generates a first voltage indicative of the detected azimuth.

The rotary potentiometer **13** is a variable resistor. In an example, the resistance value of the rotary potentiometer **13** can be changed by rotating a knob. FIG. 3A shows an

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example of the radio transmitting device **10** with a knob **13a** attached to the surface of the radio transmitting device **10**. The knob **13a** can be turned to adjust the resistance of the rotary potentiometer **13** in the radio transmitting device **10**.

In an example, the rotary potentiometer **13** generates a second voltage based on the rotation position of the knob **13a**. For example, amplitude of the second voltage is proportional to the rotation angle of the knob **13a**. The second voltage is provided to the controller **11** to indicate the rotation angle of the knob **13a**.

According to an aspect of the disclosure, at a time when an operator installs the radio transmitting device **10**, the operator can adjust the knob **13a** of the rotary potentiometer **13** to indicate a specific azimuth. In an example, the specific azimuth is a true azimuth at the position of the installation. The specific azimuth can be measured by a different device using a different technology.

The controller **11** receives the first voltage from the geomagnetic sensor **12** and the second voltage from the rotary potentiometer **13**, and calculates a difference between the first voltage and the second voltage. In an example, based on the difference, the controller **11** determines the correction data. In an example, the correction data is indicative of an angle difference of the detected azimuth by geomagnetic sensor **12**, and the specific azimuth set by the rotary potentiometer **13**.

It is noted that the output of the geomagnetic sensor **12** is not limited to voltage, and can have any suitable form to indicate the detected magnetic direction. In an example, the geomagnetic sensor **12** outputs a digital value that indicates the magnetic direction. Further, the rotary potentiometer **13** can output another digital value indicative of the specific azimuth. Then, the controller **11** can receive the two digital values from the geomagnetic sensor **12** and the rotary potentiometer **13**, calculate a difference and determine the correction data based on the difference.

In an example, the controller **11** is implemented by circuits. In another example, the controller **11** is implemented as a processing circuitry executing software instructions.

In an example, the controller **11** provides the correction data to the wireless communication processing circuit **15**. The wireless communication processing circuit **15** generates the beacon signal to carry the correction data.

In addition, the memory **14** stores the identification code allocated to the radio transmitting device **10**. The controller **11** reads the memory **14** to obtain the identification code, and provides the identification code to the wireless communication processing circuit **15**. The wireless communication processing circuit **15** generates the beacon signal to carry the identification code. In an embodiment, the wireless communication processing circuit **15** is a short-distance wireless communication processing circuit, such as a BLE processing circuit.

The antenna **16** is coupled to the wireless communication processing circuit **15** to radio-transmit the beacon signal with a fixed period (for example, period of about one to several seconds).

In an example, the wireless communication processing circuit **15** uses a carrier frequency of about 2.4 GHz, and transmits a beacon signal according to a BLE wireless communication technology. In an example, the beacon signal can travel a distance about several meters. When the mobile device **100** is within the distance, the radio transmitting device **10** can communicate with the mobile device **100** based on the beacon signal.

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According to an aspect of the disclosure, the radio transmitting device 10 includes the power supply circuit 17 having the plug 17a. In an example, the plug 17a can be plugged with an outlet socket to receive an AC power supply. In an example, the power supply circuit 17 converts the AC power into DC power, and provides the DC power to other circuit components, such as the wireless communication processing circuit 15, the controller 11, the memory 14, the geomagnetic sensor 12, the rotary potentiometer 13, and the like in the radio transmitting device 10.

In another embodiment, the power supply circuit 17 includes a battery pack to provide DC power to other circuit components in the radio transmitting device 10.

FIG. 3A, FIG. 3B, and FIG. 3C are figures showing an example of a case structure of the radio transmitting device 10 according to an embodiment of the disclosure.

In the FIGS. 3A-3C example, the radio transmitting device 10 includes a first case portion 10a and a second case portion 10b. In the example, the first case portion 10a and the second case portion 10b are connected in a rotatable manner.

In the example, the geomagnetic sensor 12 and the rotary potentiometer 13 are disposed within the first case portion 10a. The knob 13a of the rotary potentiometer 13 is arranged on a surface 10c of the first case portion 10a. In an example, the knob 13a of the rotary potentiometer 13 can be rotated by 360 degree.

In an embodiment, the geomagnetic sensor 12 is disposed at a position with reference to the surface 10c. Thus, in an example, when the surface 10c of the first case portion 10a is leveled, the geomagnetic sensor 12 is positioned horizontally in the first case portion 10a.

In an embodiment, the power supply circuit 17 is disposed in the second case portion 10b and coupled to the plug 17a. In an example, the plug 17a can be arranged in different forms with respect to the second case portion 10b. FIG. 3A shows a first form in which the plug 17a protrudes from a bottom side of the second case portion 10b. FIG. 3B shows a second form in which the plug 17a protrudes from a bottom position of a face side of the second case portion 10b. FIG. 3C shows a third form in which the plug 17a protrudes from a side position of the face side of the second case portion 10b.

In an example, the radio transmitting device 10 is made that the plug 17a can be adjusted by 90° to switch between the first form and the second form as shown to FIG. 3B. Further, the second case portion 10b can rotate with reference to the first case portion 10c to change position of the plug 17a.

According to an aspect of the disclosure, electrical power sockets may be differently positioned. No matter how an electrical power socket is positioned, the plug 17a can be arranged to install the radio transmitting device 10 with the first surface 10c of the first case portion 10a being horizontally positioned.

FIG. 4A, FIG. 4B, and FIG. 4C are the figures explaining an example how the radio transmitting device 10 outputs correction data according to an embodiment of the disclosure.

It is noted that in an embodiment, the radio transmitting device 10 is installed with the surface 10c being arranged horizontally. The knob 13a is on the surface 10c. The geomagnetic sensor 12 in the radio transmitting device 10 is also horizontally positioned when the surface 10c is arranged horizontally.

As shown in FIG. 4A, when an operator installs the radio transmitting device 10, the operator turns the knob 13a to a

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specific direction, such as north. The north direction is confirmed using for example, a map, and the like. In FIG. 4A, the operator adjusts the knob 13a with azimuth $\theta 12$ being north. The rotary potentiometer 13 then has a resistance value corresponding to angle $\alpha 1$ from reference-axis angle $\theta 11$ to azimuth $\theta 12$ of the radio transmitting device 10. Then, the rotary potentiometer 13 outputs a voltage having a voltage value as a function of the angle $\alpha 1$.

FIG. 4B shows an azimuth $\theta 13$ (north) detected by the geomagnetic sensor 12, and an angle $\beta 1$ from the reference-axis angle $\theta 11$ of the radio transmitting device 10 to the azimuth $\theta 13$. When there is no error in the azimuth detected by the geomagnetic sensor 12, the angle $\beta 1$ of FIG. 4B corresponds (equals) to the angle $\alpha 1$ of FIG. 4A.

The angle $\beta 1$ may not equal to the angle $\alpha 1$ due to influence of surrounding environment. In an example, the angle $\beta 1$ is likely not equal to the angle $\alpha 1$ indoors.

FIG. 4C shows a correction angle $\Delta 1$ when the angle $\alpha 1$ and angle $\beta 1$ can be determined. In the FIG. 4C example, the correction angle $\Delta 1$ is calculated according to following formula:

$$\Delta 1 = \alpha 1 - \beta 1$$

In an example, the memory 14 stores the correction angle $\Delta 1$ as the correction data. The controller 11 of the radio transmitting device 10 can read the correction angle $\Delta 1$ from the memory 14. Then the controller 11 lets the beacon signal to carry the correction angle $\Delta 1$, and the beacon signal is transmitted by the wireless communication processing circuit 15.

FIG. 5 shows a flowchart outlining a process executed by the controller 11 of the radio transmitting device 10. In an example, at a time when the radio transmitting device 10 is installed, the operator sets the azimuth $\theta 12$, and the angle $\alpha 1$ from the reference-axis angle $\theta 11$ to the azimuth $\theta 12$ is determined and set in the controller 11.

At step S11: the controller 11 receives the azimuth $\theta 13$ of the reference north detected by the geomagnetic sensor 12, and calculates the angle $\beta 1$ from the reference-axis angle $\theta 11$ of the radio transmitting device 10 to the azimuth $\theta 13$.

At step S12: the controller 11 calculates correction angle $\Delta 1$. In an example, the controller 11 calculates the correction angle $\Delta 1$ as a difference between the angle $\alpha 1$ and the angle $\beta 1$. Then the controller 11 stores the correction angle $\Delta 1$ as the correction data in the memory 14.

At step S13: the controller 11 reads the correction data from the memory 14, and lets the beacon signal to carry the correction data. Then, the wireless communication processing circuit 15 radio-transmits the beacon signal that carries the correction data.

At step S14: the controller 11 waits until a next time to transmit a beacon signal. In an example, the controller 11 keeps standby a fixed period corresponding to the transmission interval of a beacon signal. At a next time to transmit the beacon signal, the process returns to the step S11.

FIG. 6 shows a block diagram of the mobile device 100 according to an embodiment of the disclosure. In an example, the mobile device 100 is a smart phone, a tablet computer, a laptop computer, a wearable electronic device, a cellular phone, a music player, a camera, and the like. The mobile device 100 has an antenna 101 and a wireless communication processing circuit 102. In an example, the wireless communication processing circuit 102 performs the base band and radio frequency signal processing.

The voice processing circuit 103 processes electrical signals corresponding to voice. The speaker 104 generates

sound waves in response to electrical signals. The microphone **105** generates electrical signals in response to sound waves.

In an example, the voice processing circuit **103** provides electrical signals in response to voice to the wireless communication processing circuit **102**. The wireless communication processing circuit **102** performs communication signal processing. The processed signal can be transmitted by the antenna **101**.

In the FIG. 6 example, the electronic device **100** includes an antenna **106** coupled to a short-distance wireless communication processing circuit **107**. In an example, the short-distance wireless communication processing circuit **107** performs wireless communications according to a Bluetooth (trademark) standard, such as Bluetooth Low Energy (BLE) standard. In an example, the short-distance wireless communication process circuit **107** receives the beacon signal transmitted from the radio transmitting device **10**.

In addition, in an example, the short-distance wireless communication process circuit **107** is configured to perform wireless communications, for example, according to a wireless local area network (WLAN) standard.

The GPS **108** receives the electromagnetic wave from one or more satellites, and measures present position based on the received electromagnetic wave.

The camera **109** generates electrical signals corresponding to images. The display **120** includes a display panel. In an example, the display panel is a liquid crystal display panel or an organic electroluminescence display panel. Characters and images can be shown on the display panel.

The touch panel **130** includes touch sensors which detect a touch, such as a figure touch, a pen touch, and the like on the surface of the display panel. In an embodiment, electrostatic capacitance type touch sensors are used. In an example, the touch panel **130** is integrated with the display **120**.

The controller **110** controls various parts of the mobile device **100** based on for example the data detected by the touchscreen part **130** or the operation key **140**.

In an example, the display **120** shows a keyboard etc., the controller **110** controls a displaying condition.

The memory **150** stores data and software instructions. In an embodiment, the controller **110** is implemented as a processing circuitry executing software instructions. In another embodiment, the controller **110** is implemented as circuits.

The acceleration sensor **161** detects an acceleration of the mobile device **100**. The detection data of acceleration by the acceleration sensor **161** can be provided to the controller **110**.

The geomagnetic sensor **162** detects an azimuth from a terrestrial magnetism. The detection data of the azimuth can be provided to the controller **110**.

The gyroscope **163** detects the angular velocity of the mobile device **100**. The detection data of the angular velocity can be supplied to the controller **110**.

The atmospheric-pressure sensor **164** detects the atmospheric pressure around the mobile device **100**. The detection data of the atmospheric pressure can be supplied to the controller **110**.

In the FIG. 6 example, the mobile device **100** includes communication bus lines, such as a control bus line CL, a data bus line DL, and the like that couple the various components together. The control data from the controller **110** can be transmitted through the control bus line CL. The data line bus DL is used for transmission of voice data, display data, etc.

FIG. 7 shows a flowchart outlining an example of a terrestrial magnetism correction process according to an embodiment of the disclosure. In an example, the process is executed by the controller **110**.

At step S21: the controller **110** determines whether the short-distance wireless communication process circuit **107** receives a beacon signal from the radio transmitting device **10**. When a beacon signal with correction data is received from the radio transmitting device **10**, the process proceeds to S22; otherwise, the process stays at step S21 until a beacon signal is received.

In an example, when a received beacon signal does not carry the correction data for a geomagnetic sensor, the process stays at step S21 until a beacon signal with the correction data is received.

At step S22: the controller **110** extracts the correction data carried in the received beacon signal, and obtains correction angle $\Delta 1$ from the extracted correction data.

At step S23: the controller **110** acquires azimuth $\gamma 1$ detected by the geomagnetic sensor **162** in the mobile device **100**.

At step S24: the controller **110** calculates corrected azimuth θa as a sum of the correction angle $\Delta 1$ and the azimuth $\gamma 1$ detected by the geomagnetic sensor **162**. Then, the controller **110** uses the corrected azimuth θa to perform a position detection. In an example, the process then return to S21 to wait for a beacon signal.

FIG. 8 shows an example of the azimuth correction process according to an embodiment of the disclosure. In the example, the controller **110** in the mobile device **100** performs the process to correct the detection data of the geomagnetic sensor **162**. The geomagnetic sensor **162** is disposed in the mobile device **100** to detect the azimuth $\theta 22$ which is the azimuth north to be used as a reference. At a time, the controller **110** calculates an angle $\gamma 1$ from azimuth $\theta 22$ to a reference-axis $\theta 21$ of the mobile device **100**. Then, the controller **110** adds the correction angle $\Delta 1$ to angle $\gamma 1$ to obtain the corrected azimuth θa .

The mobile device **100** uses the correction data transmitted from the radio transmitting device **10** to correct the azimuth detected by the geomagnetic sensor **162** in the mobile device **100**.

According to an aspect of the disclosure, the azimuth detection error is location dependent. At different locations, the geomagnetic sensor **162** in the mobile device **100** may have different azimuth detection error. In an example, the geomagnetic sensor **162** may have a relatively large azimuth detection error when the mobile device **100** is indoors.

In an embodiment, the radio transmitting device **10** is installed at a location, the rotary potentiometer **13** is set to indicate azimuth north that is used as the reference, and the geomagnetic sensor **12** is used to determine the location dependent error and to generate correction data for the location.

In an example, when the mobile device **100** is in a close vicinity of the radio transmitting device **10** to be able to receive the beacon signal from the radio transmitting device **10**, the geomagnetic sensor **162** generates similar location dependent error as the geomagnetic sensor **12**. Using the correction data determined based on the geomagnetic sensor **12**, the azimuth detected by the geomagnetic sensor **162** detected can be corrected. With the location dependent error being corrected in the detected azimuth by the geomagnetic sensor **162**, the mobile device **100** can perform more accurate position detection using autonomous navigation.

FIG. 9 is a diagram of another example of azimuth detection according to an embodiment of the disclosure. In

the FIG. 9 example, two mobile devices **100a** and **100b** can communicate and perform azimuth detection and correction. Each of the mobile devices **100a** and **100b** can be configured similarly as the example shown in FIG. 6, and each of the mobile devices **100a** and **100b** has a respective geomagnetic sensor.

Further, each of the mobile devices **100a**, **100b** includes a short-distance wireless communication process circuit **107** that performs wireless communications according to, for example, a Bluetooth standard or wireless LAN standard.

In the FIG. 9 example, between the two devices, the mobile device **100a** is a master device and the mobile device **100b** is a slave device. The master mobile device **100a** and slave mobile device **100b** enter a state in which both devices can transfer data mutually.

In an embodiment, the master mobile device **100a** detects an angle between a reference axis and an azimuth north detected by the geomagnetic sensor in the master mobile device **100a**.

For example, as shown in FIG. 9, the master mobile device **100a** has a reference axis $\theta 31$ that is a center case line passing through the upper and lower sides on the case of the master mobile device **100**. The geomagnetic sensor in the master mobile device **100a** detects north azimuth $\theta 32$, and calculates angle $\alpha 2$ between the reference axis $\theta 31$ and north azimuth $\theta 32$. The master mobile device **100a** transmits the angle $\alpha 2$ as the correction data to the slave mobile device **100b**. The master mobile device **100a** can transmit the correction data to the slave mobile device **100b** at any time.

The slave mobile device **100b** detects a reference axis $\theta 42$ which is the case center line passing through the upper and lower sides on the case of the slave mobile device **100b**. Further, the slave mobile device **100b** detects the azimuth north $\theta 41$ using the geomagnetic sensor in the slave mobile device **100b**. Then the slave mobile device **100b** calculates angle $\beta 2$ which is the difference between the reference axis $\theta 42$, and north azimuth $\theta 41$.

Based on the correction data, the slave mobile device **100b** calculates an angle θb with reference to the reference-axis $\theta 31$ of master mobile device **100a**. In the FIG. 9 example, the slave mobile device **100b** calculates angle θb using the equation: $\theta b = \beta 2 - \alpha 2$. The angle θb is the angle between the reference axis of the slave mobile device **100b** to the reference axis of the master mobile device **100a**. Further, based on the angle θb , and the reference axis of itself, the slave mobile device **100b** can determine an axis $\theta 43$ which is about the same as the reference-axis $\theta 31$ of master mobile device **100a**.

In an embodiment, the two mobile devices **100a** and **100b** can detect positions based on a same reference axis, such as the reference axis of the master mobile device **100a**. Thus, the two mobile devices **100a** and **100b** can align position detection, and achieve about the same precision to perform autonomous navigation.

In the FIG. 9 example, the mobile devices **100a**, **100b** transmit correction data by Bluetooth standard or wireless LAN standard. In another example, the correction data can be transmitted via a server. For example, the server stores and transmits the position data measured by each of the mobile devices **100a**, **100b**.

FIGS. 10A and 10B show an example in which the mobile devices **100a**, **100b** respectively perform an autonomous navigation independently.

As shown to FIG. 10A, initially, the slave mobile device **100b** is in a range NT1 where the electromagnetic wave from master mobile device **100a** can be received. Thus, the

slave mobile device **100b** receives the correction data transmitted from master mobile device **100a**.

Based on the received correction data, the two mobile devices **100a** and **100b** can perform autonomous navigation with regard to a same reference axis and can align position detection.

FIG. 10B shows a situation in which the mobile devices **100a**, **100b** move away from the initial position P1. In the FIG. 10B example, the master mobile device **100a** moves away as indicated by M1 to a new position. With the movement, the communication area of the master mobile device **100a** changes to a range NT2 centering at the new position.

The slave mobile device **100b** moves away as indicated by M2 to a new position. The new position of the slave mobile device **100b** is out of the range NT2.

At the new positions, each of the mobile devices **100a** and **100b** detects respective present position using autonomous navigation. In an embodiment, the mobile devices **100a** and **100b** can use a same reference axis determined initially when they are in close vicinity, to detect the new positions, thus the new positions can be detected at about the same precision.

Further, in the FIG. 10B example, the slave mobile device **100b** can notify its new position to the master mobile device **100a** via a server. When the master mobile device **100a** receives the notification, the master mobile device **100a** can show the present position of the slave mobile device **100b** on a display.

Similarly, the master mobile device **100a** can notify its new position to the slave mobile device **100b** via a server. When the slave mobile device **100b** receives the notification, the slave mobile device **100b** can show on a display the present position of the master mobile device **100a**.

FIG. 11 shows a flowchart outlining a process example executed by the controller **110** of the master mobile device **100a**.

At step S31: the controller **110** establishes wireless communication with the slave mobile device **100b** using, for example, the short-distance wireless communication process circuit **107**.

At step S32: the controller **110** determines an angle $\alpha 2$ which is the angle from the reference-axis $\theta 31$ of the master mobile device **100a** to the azimuth north $\theta 32$ detected by a geomagnetic sensor **162** in the master mobile device **100a**.

At step S33: the short-distance wireless communication process circuit **107** transmits the correction data, such as the angle $\alpha 2$, to the slave mobile device **100b**.

At step S34: the controller **110** uses the detection data by the acceleration sensor **161**, the gyroscope **163** and the geomagnetic sensor **162**, and starts the autonomous navigation to measure present position. For example, the acceleration sensor **161** detects an acceleration of the mobile device **100**. The geomagnetic sensor **162** detects an azimuth from a terrestrial magnetism. The azimuth is used as a reference. The gyroscope **163** detects the angular velocity of the mobile device **100** that indicative of the direction change. Based on the azimuth and the angular velocity, the direction can be determined. Based on the acceleration and the direction, travel distance can be determined and the present location can be determined. In an example, the autonomous navigation can use a pedestrian dead-reckoning (PDR) method to determine the present position.

At step S35: the controller **110** waits for a period of time, such as a fixed period of time.

At step S36: the controller **110** determines whether the short-distance wireless communication process circuit **107**

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can communicate to the slave mobile device **100b**. In an example, when the short-distance wireless communication process circuit **107** is able to receive a signal from the slave mobile device **100b**, the controller **110** determines that the short-distance wireless communication process circuit **107** is able to communicate to the slave mobile device **100b**, and the process returns to step **S32**.

When the short-distance wireless communication process circuit **107** receives no signal from the slave mobile device **100b**, the controller **110** determines that the slave mobile device **100b** may be out of a reachable range, then the process proceeds to step **S37**.

At step **S37**: the controller **110** receives position data of slave mobile device **100b** from a server using wireless communications. It is noted that position data can be received by the short-distance wireless communication process circuit **107** or by the wireless communication processing section **102**. Then the process returns to **S36**.

FIG. **12** shows a flowchart outlining a process example executed by the controller **110** in the slave mobile device **100b**.

At step **S41**: the controller **110** establishes wireless communication with the master mobile device **100a** using the short-distance wireless communication process circuit **107**.

At step **S42**: the controller **110** receives correction data, such as the angle $\alpha 2$, from signals transmitted from the master mobile device **100a**.

At step **S43**: the controller **110** calculates the angle $\beta 2$. The angle $\beta 2$ is calculated as an angle from the reference-axis $\theta 42$ of the mobile device **100b** to the azimuth north $\theta 41$ detected by the geomagnetic sensor **162** in the slave mobile device **100b**. In an embodiment, when the master mobile device **100a** and the slave mobile device **100b** are in a close vicinity to be able to communicate using a short-distance wireless communication standard, the master mobile device **100a** and the slave mobile device **100b** have about the same surrounding environment. Thus, the geomagnetic sensors **162** in the master mobile device **100a** and the slave mobile device **100b** detect about the same azimuth north. Thus, the azimuth north $\theta 32$ is about the same as the azimuth north $\theta 41$.

At step **S44**: the controller **110** calculates the angle θb . The angle θb is the difference between $\beta 2$ and $\alpha 2$.

At step **S45**: the controller **110** uses the detection data of the acceleration sensor **161**, the gyroscope **163** and the geomagnetic sensor **162**, and starts the autonomous navigation to measure present position. In an example, the autonomous navigation can use a pedestrian dead-reckoning (PDR) method to determine the present position.

At step **S46**: the controller **110** waits for a period of time, such as a fixed period of time.

At step **S47**: the controller **110** determines whether the short-distance wireless communication process circuit **107** can communicate to the master mobile device **100a**. In an example, when the short-distance wireless communication process circuit **107** is able to receive a signal from the master mobile device **100a**, the controller **110** determines that the short-distance wireless communication process circuit **107** is able to communicate to the master mobile device **100a**, and the process returns to step **S42**.

When the short-distance wireless communication process circuit **107** receives no signal from the master mobile device **100a**, in an example, the controller **110** determines that the master mobile device **100a** is not in a close vicinity, then the process proceeds to step **S48**.

At step **S48**: the controller **110** controls the short-distance wireless communication process circuit **107** or the wireless

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communication processing section **102** to transmit the positional information of the slave mobile device **100b** to a server, and the process returns to step **S47**.

According to an aspect of the disclosure, using the processes shown in FIG. **11** and FIG. **12**, the mobile devices **100a** and **100b** can use about the same reference-axis. Thus, the mobile devices **100a** and **100b** can achieve substantially the same precision to detect position using autonomous navigation. Moreover, the master mobile device **100a** can determine the correct position of the slave mobile device **100b**.

In the example of FIG. **1**, the radio transmitting device **10** can transmit a beacon signal using a wireless communication system, such as BLE system, wireless LAN and the like. The beacon signal carries correction data.

In the example of FIG. **9**, the master mobile device **100a** can transmit signals that carry correction data to the slave mobile device **100b** using a wireless communication system, such as BLE system, a wireless LAN and the like.

It is noted that any suitable apparatus which has a wireless communication function can transmit the correction data of a geomagnetic sensor to a surrounding mobile device to assist position detection. For example, access points for a wireless LAN can transmit the correction data of a geomagnetic sensor to a surrounding mobile device.

In an embodiment, the controller **11** or controller **110** is implemented as circuits. In another embodiment, the functions of the controller **11** or the controller **110** are implemented as software to be executed by a processing circuit. The software can be installed in an existing wireless communication apparatus with a geomagnetic sensor. In an example, the software can be executed in the existing wireless communication apparatus to generate correction data for azimuth detection and to transmit the correction data. In another example, the software can be executed in the existing wireless communication apparatus to receive correction data and correct azimuth detection based on the correction data.

When implemented in hardware, the hardware may comprise one or more of discrete components, an integrated circuit, an application-specific integrated circuit (ASIC), etc.

While aspects of the present disclosure have been described in conjunction with the specific embodiments thereof that are proposed as examples, alternatives, modifications, and variations to the examples may be made. Accordingly, embodiments as set forth herein are intended to be illustrative and not limiting. There are changes that may be made without departing from the scope of the claims set forth below.

What is claimed is:

1. A radio transmitting device comprising:

- a memory configured to store correction data for correcting an azimuth angle detected by a device in a surrounding range around a location where the radio transmitting device is installed;
- a controller configured to calculate the correction data based on a reference angle;
- a wireless communication processing circuit configured to transmit a radio signal to carry the correction data to assist the device in the surrounding range to correct the azimuth angle; and
- a potentiometer communicatively coupled with a knob, the potentiometer configured to be positioned horizontally to the ground and the knob configured to be manually turned by a user at installation to align with one of geographic cardinal directions for indicating the reference angle, wherein the knob stays as aligned with

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the one of geographic cardinal directions until the user manually turns the knob again.

2. The radio transmitting device of claim 1, wherein the memory is configured to store an error correction angle for correcting the azimuth angle.

3. The radio transmitting device of claim 1, wherein the wireless communication processing circuit is configured to transmit the radio signal as a beacon signal that is transmitted periodically to carry the correction data.

4. The radio transmitting device of claim 1, wherein the wireless communication processing circuit is configured to transmit the radio signal according to a short distance wireless communication standard.

5. The radio transmitting device of claim 1, further comprising:
a geomagnetic sensor configured to measure the azimuth angle at the location.

6. The radio transmitting device of claim 5, further comprising:
a reference angle device configured to generate an electrical signal in response to the reference angle;
wherein the controller is configured to calculate the correction data based on the reference angle and the azimuth angle detected by the geomagnetic sensor.

7. The radio transmitting device of claim 6, wherein reference angle device includes the potentiometer for indicating the reference angle.

8. The radio transmitting device of claim 7, further comprising:
a plug for connection to an AC power source; and
a rotary mechanism configured to adjust a relative angle between the plug and the potentiometer.

9. A mobile device comprising:
a geomagnetic sensor configured to detect an azimuth angle;
a wireless communication processing circuit configured to receive a radio signal carrying correction data for correcting the azimuth angle, the correction data calculated based on a reference angle indicated by a potentiometer communicatively coupled with a knob, the potentiometer configured to be positioned horizontally to the ground and the knob configured to be manually turned by a user at installation to align with one of geographic cardinal directions for indicating the reference angle, wherein the knob stays as aligned with the one of geographic cardinal directions until the user manually turns the knob again; and
a controller configured to correct the azimuth angle detected by the geomagnetic sensor based on the correction data carried in the radio signal.

10. The mobile device of claim 9, wherein the wireless communication processing circuit is configured to receive a beacon signal carrying the correction data; and
the controller is configured to exact the correction data from the beacon signal.

11. The mobile device of claim 9, wherein the radio signal carrying the correction data for correcting the azimuth angle was transmitted from another mobile device.

12. The mobile device of claim 11, wherein the controller is configured to calculate an alignment angle based on the

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correction data and the azimuth angle to align a reference used by the mobile device and the other mobile device for position detection.

13. The mobile device of claim 9, wherein the wireless communication processing circuit is configured to receive the radio signal carrying correction data for correcting the azimuth angle according to a short distance wireless communication standard.

14. A method for detecting azimuth angle comprising:
indicating a reference angle by a potentiometer communicatively coupled with a knob, the potentiometer configured to be positioned horizontally to the ground and the knob configured to be manually turned by a user at installation to align with one of geographic cardinal directions for indicating the reference angle, wherein the knob stays as aligned with the one of geographic cardinal directions until the user manually turns the knob again;

calculating correction data based on the reference angle; receiving, by a wireless communication processing circuit in a mobile device, a radio signal carrying the correction data for azimuth angle correction;
detecting, by a geomagnetic sensor, an azimuth angle; and correcting the azimuth angle based on the correction data carried in the radio signal.

15. The method of claim 14, wherein receiving, by the wireless communication processing circuit in the mobile device, the radio signal carrying the correction data for azimuth angle correction further comprises:

receiving a beacon signal carrying the correction data.

16. The method of claim 15, further comprising:
processing the beacon signal to extract the correction data.

17. The method of claim 14, wherein receiving, by the wireless communication processing circuit in the mobile device, the radio signal carrying the correction data for azimuth angle correction further comprises:

receiving the radio signal which is transmitted from a radio transmitting device which is installed at a location to transmit the correction data associated with the location.

18. The method of claim 14, wherein receiving, by the wireless communication processing circuit of the mobile device, the radio signal carrying the correction data for azimuth angle correction further comprises:

receiving the radio signal which is transmitted from another mobile device.

19. The method of claim 18, further comprising:
calculating an alignment angle based on the correction data and the azimuth angle; and
aligning a reference used by the mobile device and the other mobile device for position detection.

20. The method of claim 14, wherein receiving, by the wireless communication processing circuit in the mobile device, the radio signal carrying the correction data for azimuth angle correction further comprises:

receiving the radio signal carrying correction data for correcting the azimuth angle according to a short distance wireless communication standard.

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